

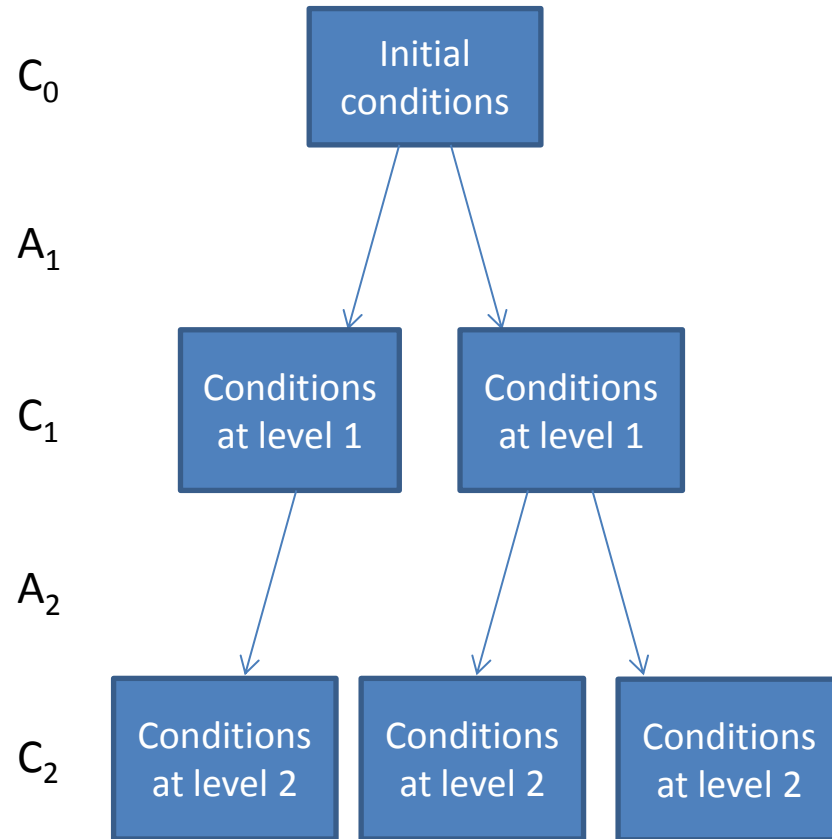
Graphplanner

Possible actions:

- Reach
- Grasp
- Drop
- Grasp_tool
- Drop_tool

Set of initial conditions:

- Visible objects
- Grasped object (if any)
- Current tool (if none, then the default is the hand)



Planning is performed by backtracking from the goal, on the graph, until we reach initial conditions. Mutual exclusivity links in the tree speed up the process. Backtracking is performed by iterative deepening depth-first-search.